

## AMENDMENTS TO THE SPECIFICATION

Please amend the Specification on page 10, the paragraph beginning at line 5:

Again as is shown in Figures 1 and 3, my preferred embodiment may also include gripping means to selectively reposition each container C prior to and/or during removal of the items I. The gripping means may comprise a pair of piercing points 40 which are mounted to linear actuators 45 for selectively retracting and extending. The actuators preferably include a linear slide 37 (see Figure 3) and/or a fluid cylinder, as is commonly understood in the art. The controller 50 controls the movement of the actuators 45. The actuators 45 are coupled to a mounting arm 38. The mounting arm 38 is mounted generally perpendicular to the plate 28. In my preferred embodiment the pair of piercing points 40 each include a barbed portion 41 located at an end of a round shaft 43. The barbed portion 41 is adapted to pierce a sidewall of the container C when selectively extended by the linear slide and fluid cylinder 45. To control encroachment of the piercing points 40 toward the mounting arm 38, each point 40 may preferably include a bumper 42 located on the extendable shaft 43 at a predetermined position behind the barbed portion 41.

Please amend the Specification on page 11, the paragraph beginning at line 8:

As customary in the robotic arts, the end effector 20 may be rotatably mounted on a robotic arm A so that the effector 20 may rotate about a radial axis. Accordingly, the robot is capable of positioning the end effector 20 at any desired location. Thus, it is understood that the end effector 20 has a varied and useful range of motion. As shown in Figure 9, a stanchion or wrist spacer 48 is provided to receive the distal end 52 of the robotic arm A ~~at its proximate end 52~~. The distal end 49 (see Figure 4) of the wrist spacer 50 48 is connected to a the frame 26. A plurality of fasteners 51 is used to retain the structures together.